

**THE CATHOLIC UNIVERSITY OF AMERICA  
DEPARTMENT OF ELECTRICAL ENGINEERING**

**SEMIANNUAL PROGRESS REPORT  
on  
A STUDY OF SPACE-RATED CONNECTORS  
USING A ROBOTIC END-EFFECTOR**

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## REPORT SUMMARY

*This is a semiannual report presenting the research results obtained from the research grant entitled "A Study of Space-Rated Connectors using a Robotic End-effector," funded by the Goddard Space Flight Center (NASA) under a research grant with Grant Number NAG 5-1415, for the period between November 1, 1990 and February 28, 1991.*

*This report presents the kinematic analysis of a 6 DOF force sensor whose design is based on the mechanism of the Stewart Platform. The force sensor is used to measure forces/torques and to provide passive compliance during part assembly. It is mainly composed of two platforms, the payload platform and the end-effector platform, coupled together through six spring-loaded pistons whose length variations are measured by six linear voltage differential transformers (LVDT) mounted along the pistons. The forces and torques applied to the end-effector platform are computed using the inverse and forward kinematic transformations of the Stewart Platform, the known spring constants, and the piston length variations. Computation of forces and torques using vector algebra is presented. Results of experiments conducted to evaluate the sensing capability of the force sensor used during the mating and demating of space-rated connectors are reported and discussed.*

# 1 Introduction

For high precision tasks where the requirements of accuracy and sturdiness outweigh these of large workspace and maneuverability, closed-kinematic chain (CKC) mechanisms are more often employed than the conventional anthropomorphic open-kinematic chain (OKC) mechanism to design robotic manipulators, end-effectors and devices performing the tasks [1]-[27]. This comes from the fact that CKC robots are generally sturdier and more precise than OKC robots because of the closed chain nature of their mechanisms. Having links and joints actuating in series and being compact, OKC robots possess long reach, large workspace and are capable of entering small spaces. However the cantilever-like structure causes them to have low stiffness and undesired dynamic characteristics, especially at high speed and large payload. Moreover, due to the nonuniform distribution of payload to actuators and serial accumulation of joint errors throughout the OKC mechanism, OKC robots have low strength-to-weight ratios and are not capable of providing high precision motion needed in robotic assembly tasks. On the other hand, CKC robots whose mechanism are parallel, have been considered in numerous robotic applications because of their high structural rigidity and non-serial accumulation of joint and link errors. One of the first applications of CKC mechanism appeared in the design of the Stewart Platform [1] which was later employed by Dieudonne and his coworkers [2] to design an aircraft simulator at the NASA Langley Research Center. Hoffman and McKinnon [3] used a finite element program to simulate the motion of the Stewart Platform whose mechanism was later applied by McCallion and Truong [4] to design an automatic table. Hunt [5,7] studied the structural kinematic problem of in-parallel-actuated robot manipulators. Applying linear algebra elements to screw systems, Sugimoto and Duffy [6] developed a general method to describe the instantaneous link motion of a single closed-loop mechanism. In order to investigate autonomous part assembly in space, Premack and others [8] of NASA/Goddard Space Flight Center designed and built a passive compliant robot end-effector whose active compliance problem was later investigated by Nguyen and his coworkers [9]. The kinematic problems and practical construction of the Stewart Platform were considered by Yang and Lee [10], Mohammed and Duffy [11], and Fichter [12]. Sugimoto [13] studied kinematics and dynamics of parallel manipulators and Lee and his coworkers [14] derived dynamical equations for a 3 degree-of-freedom (DOF) manipulator. Rees-Jones [15] applied screw theory to treat Stewart Platform-based manipulators while Sharon and others [17] applied the Stewart Platform mechanism to design a micromanipulator performing fine motion. The Stewart Platform mechanism was also applied by Kerr [19] to manufacture a force/torque sensor. Other problems of Stewart Platform-based manipulators such as adaptive force/torque control, kinematics, dynamics and workspace computation were treated by Nguyen and his coworkers [20,22,23]. Closed-form solutions of forward kinematics were derived by Griffis and Duffy [21] and Nanua and others [24] for a class of Stewart Platforms. Nguyen and others [25,26] developed learning control and trajectory planning schemes for parallel manipulators and presented experimental

results of the trajectory planning schemes in [27].

This report deals with the kinematic analysis and experimentation of a six-degree-of-freedom force/torque sensor whose design is based on the mechanism of the Stewart Platform. The report is organized as follows. Section 2 describes and explains the functions of the main components of the force/torque sensor system. Sections 3 and 4 present the solutions to inverse and forward kinematics of the force/torque sensor, respectively. Vector equations are developed in Section 5 for computing forces/torques. Section 6 presents results of experiments conducted to evaluate the sensing capability of the force sensor. Finally the content of the report will be reviewed and future research activities will be outlined in Section 7.

## 2 The Force/Torque Sensor System

Figure 1 presents the force/torque system which mainly consists of a 6 DOF force/torque sensor, a data acquisition system and an AT 286 personal computer. The main components and the functions of the force/torque sensor and the data acquisition system are described below.

### 2.1 The Force/Torque Sensor

Figure 2 shows the force sensor<sup>1</sup> which is composed of an upper compliant platform (UCP) and a lower compliant platform (LCP) coupled together through six spring-loaded pistons arranged in a geometry similar to the mechanism of the Stewart Platform. Universal joints are used to mount the pistons to the two platforms. A gripper is attached to the LCP to perform assembly of parts. The pistons permit strain on two opposing springs acting in each piston. They are compressed or extended when resistive or gravitational forces are exerted on the gripper. Thus the force sensor mechanism also serves as a passive compliant device which provides compliance to the gripper during an assembly task. TRANS-TEK DC-DC gaging linear voltage differential transformers (LVDT) are mounted along the pistons to measure the deflection of the springs, which will be used to calculate forces/torques applied to gripper. The supply voltage is provided by a KEPCE ATE 15-3P power supply, a very stable variable voltage power supply which is especially suitable for high precision measurement.

### 2.2 The Data Acquisition System

As presented in Figure 1, LVDT analog signals representing the corresponding spring deflections are processed through a CAMAC data acquisition system which consists of an Analog-to-Digital Converter (ADC) board, a Display Controller board, a Dataway display board, a CRATE controller board, and a Personal Computer (PC) interface

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<sup>1</sup>For simplicity, from now on, *force sensor* is used to denote *force/torque sensor*.

board, all contained in a CAMAC Crate. The CAMAC Crate acts as a house for up to 25 boards and several busways for board communication, and provides DC power to the boards. The ADC board can convert up to 16 analog voltages into equivalent digital values using a sample-and-hold amplifier and a successive-approximation converter. The LVDT signals are continuously scanned and converted, and the results are then stored in the module's 16-word memory. The Dataway Display module indicates the state of all the Dataway signal lines during a Dataway cycle. It contains two 24-bit registers, designated as Data and Command register whose outputs are continuously displayed by front-panel LEDs. The Crate Controller provides an asynchronous, parallel data path between a CAMAC crate and a parallel I/O port of a computer. A 50-contact, flat-ribbon connector is used for the reception and transmission of all necessary data and control lines between the Crate Controller and the interface device which are 16 bits wide. The Crate Controller is accessed by calling assembly language routines which indicate to the system the type of information requested.

### 3 Force Sensor Inverse Kinematics

This section presents the development of kinematic equations which can be used to convert the piston lengths measured by the LVDTs into the corresponding pose<sup>2</sup> of the LCP with respect to the UCP. Figure 3 shows two right-hand coordinate frames  $\{A\}$  and  $\{E\}$  assigned to the UCP and LCP, respectively. The Centroid A of the UCP is chosen to be the origin of Frame  $\{A\}$ , the  $z_A$ -axis is pointing outward and the  $x_A$ -axis is perpendicular to the line connecting the two attachment points  $A_1$  and  $A_6$ . In addition,  $\theta_A$  denotes the angle between  $A_1$  and  $A_2$ . The angles between  $A_1$  and  $A_3$  and between  $A_3$  and  $A_5$  are set to  $120^\circ$  to obtain a symmetrical distribution of joints on the UCP. Similarly, the Centroid E of the LCP is the origin of Frame  $\{E\}$ , the  $x_E$ -axis is perpendicular to the line connecting the two attachment points  $E_1$  and  $E_6$ , and  $\theta_E$  denotes the angle between  $E_1$  and  $E_2$ . Also the angles between  $E_1$  and  $E_3$  and between  $E_3$  and  $E_5$  are set to  $120^\circ$  in order to symmetrically distribute the joints on the LCP. The Cartesian variables are chosen to be the relative pose of Frame  $\{E\}$  with respect to Frame  $\{A\}$  where the position of Frame  $\{E\}$  is specified by the position of its origin with respect to Frame  $\{A\}$ . Now if we denote the angle between  $AA_i$  and  $x_A$  by  $\lambda_i$ , and the angle between  $EE_i$  and  $x_E$  by  $\Lambda_i$  for  $i=1,2,\dots,6$ , then

$$\Lambda_i = 60i^\circ - \frac{\theta_E}{2}; \lambda_i = 60i^\circ - \frac{\theta_A}{2}, \text{ for } i = 1, 3, 5 \quad (1)$$

and

$$\Lambda_i = \Lambda_{i-1} + \theta_E; \lambda_i = \lambda_{i-1} + \theta_A, \text{ for } i = 2, 4, 6. \quad (2)$$

Furthermore, if Vector  ${}^E\mathbf{e}_i = (e_{ix} \ e_{iy} \ e_{iz})^T$  describes the position of the attachment point  $E_i$  with respect to Frame  $\{E\}$ , and Vector  ${}^A\mathbf{a}_i = (a_{ix} \ a_{iy} \ a_{iz})^T$  the position of the

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<sup>2</sup>In this report, *pose* implies both *position* and *orientation*.

attachment point  $A_i$  with respect to Frame  $\{A\}$ , then they can be written as

$${}^E\mathbf{e}_i = \begin{bmatrix} r_E \cos(\lambda_i) & r_E \sin(\lambda_i) & 0 \end{bmatrix}^T \quad (3)$$

and

$${}^A\mathbf{a}_i = \begin{bmatrix} r_A \cos(\Lambda_i) & r_A \sin(\Lambda_i) & 0 \end{bmatrix}^T \quad (4)$$

for  $i=1,2,\dots,6$  where  $r_A$  and  $r_E$  represent the radii of the UCP and LCP, respectively.

Let us now consider the vector diagram for an  $i$ th piston given in Figure 4. The position of Frame  $\{E\}$  is represented by Vector  ${}^A\mathbf{d} = [x \ y \ z]^T$  which contains the Cartesian coordinates  $x, y, z$  of the origin of Frame  $\{E\}$  with respect to Frame  $\{A\}$ . The length vector  ${}^A\mathbf{q}_i = (q_{ix} \ q_{iy} \ q_{iz})^T$ , expressed with respect to Frame  $\{A\}$  can be computed by

$${}^A\mathbf{q}_i = {}^A\mathbf{x}_i + {}^A\mathbf{e}_i \quad (5)$$

where

$${}^A\mathbf{x}_i = {}^A\mathbf{d} - {}^A\mathbf{a}_i \quad (6)$$

$$= \begin{bmatrix} x - a_{ix} \\ y - a_{iy} \\ z - a_{iz} \end{bmatrix} = \begin{bmatrix} x - a_{ix} \\ y - a_{iy} \\ z \end{bmatrix} = \begin{bmatrix} \bar{x}_i \\ \bar{y}_i \\ \bar{z}_i \end{bmatrix} \quad (7)$$

which is a shifted vector of  ${}^A\mathbf{d}$  and

$${}^A\mathbf{e}_i = {}^A_E\mathbf{R} \ {}^E\mathbf{e}_i \quad (8)$$

$$= \begin{bmatrix} r_{11} & r_{12} & r_{13} \\ r_{21} & r_{22} & r_{23} \\ r_{31} & r_{32} & r_{33} \end{bmatrix} \begin{bmatrix} e_{ix} \\ e_{iy} \\ e_{iz} \end{bmatrix} = \begin{bmatrix} r_{11}e_{ix} + r_{12}e_{iy} \\ r_{21}e_{ix} + r_{22}e_{iy} \\ r_{31}e_{ix} + r_{32}e_{iy} \end{bmatrix} = \begin{bmatrix} u_i \\ v_i \\ w_i \end{bmatrix} \quad (9)$$

which is the representation of  ${}^A\mathbf{e}_i$  in Frame  $\{A\}$  and  ${}^A_E\mathbf{R}$  is the *Orientation Matrix* representing the orientation of Frame  $\{E\}$  with respect to Frame  $\{A\}$ .

Thus the length  $l_i$  of Vector  ${}^A\mathbf{q}_i$  can be computed from its components as

$$l_i = \sqrt{q_{ix}^2 + q_{iy}^2 + q_{iz}^2}. \quad (10)$$

or

$$l_i = \sqrt{(\bar{x}_i + u_i)^2 + (\bar{y}_i + v_i)^2 + (\bar{z}_i + w_i)^2} \quad (11)$$

We obtain from (3)-(4)

$$e_{ix}^2 + e_{iy}^2 + e_{iz}^2 = r_E^2, \quad (12)$$

$$a_{ix}^2 + a_{iy}^2 + a_{iz}^2 = r_A^2. \quad (13)$$

and from the properties of orientation matrix

$$r_{11}^2 + r_{21}^2 + r_{31}^2 = r_{12}^2 + r_{22}^2 + r_{32}^2 = r_{13}^2 + r_{23}^2 + r_{33}^2 = 1 \quad (14)$$

and

$$\begin{aligned}
r_{11}r_{12} + r_{21}r_{22} + r_{31}r_{32} &= 0 \\
r_{11}r_{13} + r_{21}r_{23} + r_{31}r_{33} &= 0 \\
r_{11}r_{13} + r_{22}r_{23} + r_{32}r_{32} &= 0.
\end{aligned} \tag{15}$$

Using (12)-(15), Equation (10) can be rewritten as

$$\begin{aligned}
l_i^2 = & x^2 + y^2 + z^2 + r_E^2 + r_A^2 + 2(r_{11}e_{ix} + r_{12}e_{iy})(x - a_{ix}) \\
& + 2(r_{21}e_{ix} + r_{22}e_{iy})(y - a_{iy}) + 2(r_{31}e_{ix} + r_{32}e_{iy})z \\
& - 2(xa_{ix} + ya_{iy}),
\end{aligned} \tag{16}$$

for  $i=1,2,\dots,7$ .

Equation (16) represents the *closed-form* solution to the force sensor inverse kinematics in the sense that piston lengths  $l_i$  for  $i=1,2,\dots,7$  which correspond to the pose of Frame  $\{E\}$  with respect to Frame  $\{A\}$  can be determined using (16).

The orientation of Frame  $\{E\}$  with respect to Frame  $\{A\}$  can be described by the orientation matrix  ${}^A_E\mathbf{R}$  as shown in (9) which requires nine variables  $r_{ij}$  for  $i,j=1,2,3$  from which six are redundant because only three are needed to specify an orientation [30]. There exist several ways to specify an orientation by three variables, but the most widely used one is the Roll-Pitch-Yaw angles  $\alpha$ ,  $\beta$ , and  $\gamma$ , which represent the orientation of Frame  $\{E\}$ , obtained after the following sequence of rotations from Frame  $\{A\}$ :

1. First rotate Frame  $\{A\}$  about the  $\mathbf{x}_A$ -axis an angle  $\gamma$  (*Yaw*),
2. Then rotate the resulting frame about the  $\mathbf{y}_A$ -axis an angle  $\beta$  (*Pitch*), and
3. Finally rotate the resulting frame about the  $\mathbf{z}_A$ -axis an angle  $\alpha$  (*Roll*).

The orientation represented by the above Roll-Pitch-Yaw angles is given by<sup>3</sup>

$${}^A_E\mathbf{R} = \mathbf{R}_{RPY} = \begin{bmatrix} c\alpha c\beta & c\alpha s\beta s\gamma - s\alpha c\gamma & c\alpha s\beta c\gamma + s\alpha s\gamma \\ s\alpha c\beta & s\alpha s\beta s\gamma + c\alpha c\gamma & s\alpha s\beta c\gamma - c\alpha s\gamma \\ -s\beta & c\beta s\gamma & c\beta c\gamma \end{bmatrix}. \tag{17}$$

## 4 Force Sensor Forward Kinematics

This section deals with the conversion of the lengths  $l_i$  for  $i=1,2,\dots,7$  measured by six LVDTs into the pose of Frame  $\{E\}$  with respect to Frame  $\{A\}$ . This type of conversion is the force sensor forward kinematics which can be formulated as to find a Cartesian position specified by  $x$ ,  $y$ ,  $z$  and an orientation specified by Roll-Pitch-Yaw angles  $\alpha$ ,  $\beta$ , and  $\gamma$  to satisfy Equation (16) for a given set of pistons lengths  $l_i$  for  $i=1,2,\dots,7$ .

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<sup>3</sup> $c\alpha \equiv \cos \alpha$ , and  $s\alpha \equiv \sin \alpha$ .

In general, there exists no closed-form solution for the above problem since Equation (16) represents a set of 6 highly nonlinear simultaneous equations with 6 unknowns. Consequently iterative numerical methods must be employed to solve the above set of nonlinear equations. In the following we will present the implementation of Newton-Raphson method for solving the forward kinematic problem.

In order to apply the Newton-Raphson method, first from (11) we define 6 scalar functions

$$f_i(\boldsymbol{\sigma}) = (\bar{x}_i + u_i)^2 + (\bar{y}_i + v_i)^2 + (\bar{z}_i + w_i)^2 - l_i^2 = 0 \quad (18)$$

for  $i=1,2,\dots,7$ , where the vector  $\boldsymbol{\sigma}$  is defined as

$$\boldsymbol{\sigma} = \begin{bmatrix} \sigma_1 & \sigma_2 & \sigma_3 & \sigma_4 & \sigma_5 & \sigma_6 \end{bmatrix}^T = \begin{bmatrix} x & y & z & \alpha & \beta & \gamma \end{bmatrix}^T, \quad (19)$$

and then employ the following algorithm [29] to solve for  $\boldsymbol{\sigma}$ :

### Algorithm 1: Force Sensor Forward Kinematics

**Step 1:** Select an initial guess  $\boldsymbol{\sigma}$ .

**Step 2:** Compute the elements  $r_{ij}$  of  ${}^A_E\mathbf{R}$  using (17) for  $i,j=1,2,3$ .

**Step 3:** Compute  $\bar{x}_i, \bar{y}_i, \bar{z}_i$ , using (7) and  $u_i, v_i, w_i$  using (9) for  $i=1,2,\dots,7$ .

**Step 4:** Compute  $f_i(\boldsymbol{\sigma})$  and  $A_{ij} = \frac{\partial f_i}{\partial \sigma_j}$  using (18) for  $i, j=1,2,\dots,7$ .

**Step 5:** Compute  $B_i = -f_i(\boldsymbol{\sigma})$  for  $i=1,2,\dots,7$ . If  $\sum_{j=1}^6 |B_j| < \text{tol}f$  (tolerance), stop and adopt  $\boldsymbol{\sigma}$  as the solution.

**Step 6:** Solve  $\sum_{j=1}^6 A_{ij} \delta\sigma_j = B_i$  for  $\delta\sigma_j$  for  $i,j=1,2,\dots,7$  using LU decomposition. If  $\sum_{j=1}^6 \delta\sigma_j < \text{tol}\sigma$  (tolerance), stop and adopt  $\boldsymbol{\sigma}$  as the solution.

**Step 7:** Select  $\boldsymbol{\sigma}^{\text{new}} = \boldsymbol{\sigma} + \delta\boldsymbol{\sigma}$  and repeat Steps 1–7.

## 5 Computation of Forces/Torques

In this section, we will derive mathematical expressions which utilize the spring deflections measured by the LVDTs to compute the forces applied to the gripper. The forces will be computed with respect to Frame  $\{\mathbf{A}\}$  of the UCP. When external forces are applied to the gripper, the gripper will deflect. An equilibrium is achieved when the forces created in the 6 pistons and its corresponding torques balance out the external force and torques, respectively [28]. In general, an external force applied to the gripper creates forces in the pistons and no torque about the gripper position G. An external torque which results from a pair of forces equal in magnitude, opposite in direction, and on parallel lines of action will create piston forces that cancel out each other and the



resultant torque of all the torques created by the piston forces is equal to the external torque.

We proceed to consider the vector diagram in Figure 4 which represents the LCP relative to the UCP after a set of external forces and torques are applied to a point G on the gripper. The current piston lengths,  $l_{i,new}$  for  $i=1,2,\dots,7$  can be computed by

$$l_{i,new} = l_{i,old} + \Delta l_i \quad (20)$$

where  $l_{i,old}$  for  $i=1,2,\dots,7$  are the piston lengths before the external forces and torques are applied and  $\Delta l_i$  for  $i=1,2,\dots,7$  are the changes in piston lengths, measured and provided by the LVDTs. A force vector is expressed as the product of its magnitude and the unit vector of the position vector along which the force is acting [28]. The position vector  ${}^A\mathbf{q}_i$  along which the force acts on the piston is computed by

$${}^A\mathbf{q}_i = {}^A\mathbf{d} - {}^A\mathbf{a}_i + {}^A_E\mathbf{R} {}^E\mathbf{e}_i \quad (21)$$

where  ${}^A\mathbf{d}$  and  ${}^A_E\mathbf{R}$  which represent the current position and orientation of Frame  $\{\mathbf{E}\}$  with respect to Frame  $\{\mathbf{A}\}$ , respectively, are computed by applying Algorithm 1 on  $l_{i,new}$ . Thus the force acting on the  $i$ th piston is obtained by

$$\mathbf{F}_i = K_i \Delta l_i \frac{{}^A\mathbf{q}_i}{|{}^A\mathbf{q}_i|} \quad (22)$$

where  $K_i$  denotes the equivalent spring constant of the two springs acting in the piston and  ${}^A\mathbf{q}_i/|{}^A\mathbf{q}_i|$  denotes the unit vector of the position vector along which  $\mathbf{F}_i$  acts and  $|{}^A\mathbf{q}_i|$  denotes the magnitude of the position vector. Furthermore, the extension, or compression, of the springs  $\Delta l_i$  is positive when  $\mathbf{F}_i$  is tensile and negative when  $\mathbf{F}_i$  is compressive. In other words, the force which the springs of the  $i$ th piston applies on the gripper is equal to  $-\mathbf{F}_i$ .

Thus when the gripper location G is in equilibrium, the force applied to the gripper is equal to the resultant force of the piston forces, namely

$$\mathbf{F} = \sum_{i=1}^6 \mathbf{F}_i = \sum_{i=1}^6 K_i \Delta l_i \frac{{}^A\mathbf{q}_i}{|{}^A\mathbf{q}_i|}. \quad (23)$$

As discussed above, from the fact that the torque about G caused by the external force applied at G is equal to zero, the external torque,  $\mathbf{M}$  about G is equal to the resultant torque about G caused by the piston forces when the gripper is in equilibrium. Thus

$$\mathbf{M} = \sum_{i=1}^6 {}^A\mathbf{h}_i \times \mathbf{F}_i = \sum_{i=1}^6 {}^A\mathbf{h}_i \times K_i \Delta l_i \frac{{}^A\mathbf{q}_i}{|{}^A\mathbf{q}_i|} \quad (24)$$

where

$${}^A\mathbf{h}_i = {}^A\mathbf{d} - {}^A\mathbf{a}_i + {}^A_E\mathbf{R} {}^E\mathbf{g}_i, \quad (25)$$

and  $\times$  denotes the vector product.

## 6 Experimental Verification

In this section, experiments are performed to evaluate the sensing capability of the force sensor. In the following two experiments, the data of the piston lengths provided by the LVDTs are acquired *on-line* via the data acquisition system and stored on the hard disk of the personal computer. After each experiment, computation of forces and torques are carried out *off-line* using a program written in C language, which implements the force sensor inverse and forward kinematics and the force computations. Then MATLAB is used to graphically display the obtained results. Before the experiments, the force sensor was calibrated by applying some known vertical force to the gripper using a force gauge and scaling the LVDT signals accordingly.

### Experiment 1: Measurement of Pure Torques

The first experiment is designed to test the force sensor capability of measuring pure torques. In order to apply a positive (negative) torque to the gripper, we rotate the gripper about an axis  $\mathbf{z}_G$  which emanates from G and is parallel to  $\mathbf{z}_E$ , an angle of 2 degrees (-2 degrees) while keeping the force sensor UCP at a fixed pose. Since only torque is applied to the gripper, it is expected that only torque and no force is sensed by the force sensor. Indeed, according to the experimental results, the forces acquired in the directions of  $\mathbf{x}_A$ -axis,  $\mathbf{y}_A$ -axis, and  $\mathbf{z}_A$ -axis are very negligible, which may be created by imperfect calibration of the LVDTs. Figure 5 presents the time history of the force signals. As expected, the torques about G assumes a value of 2.303 lb-in and -2.1919 lb-in when the gripper is rotated an angle of 2 degrees and -2 degrees, respectively.

### Experiment 2: Force Measurement During Connector Mating

In the second experiment, we use the force sensor to monitor the forces applied to the gripper during the mating and demating of a space-rated connector, Series 882, manufactured by G & H Technology, Inc. The UCP of the force sensor is mounted to the payload platform of a Stewart Platform-based robot manipulator [27] whose linear actuators are driven by stepper motors. The gripper motion during the connector mating/demating is created by properly controlling the motion of the stepper motors. The forces applied along the  $\mathbf{x}_A$ -axis,  $\mathbf{y}_A$ -axis and  $\mathbf{z}_A$ -axis are reported in Figures 6, 7, and 8, respectively. The mating and demating are performed in two different stages. In the first stage, the connector is mated and demated under a perfect alignment between the connector plug and the connector receptacle and in the second stage under a misalignment produced by rotating the connector plug about the  $\mathbf{z}_G$ -axis an angle of -2 degrees. The force applied in the  $\mathbf{z}_A$ -axis is the largest as compared to those applied in the  $\mathbf{x}_A$ -axis and  $\mathbf{y}_A$ -axis since the gripper motion during the mating and demating is mostly vertical. As shown in Figure 8, the forces exerted along the  $\mathbf{z}_A$ -axis during the demating in both stages are of almost the same value of about 26.23 lb. Figure 8

also shows that the maximum forces required for the mating are 28.024 lb and 39.84 lb during the first and second stage, respectively and the force is relatively disturbed during the second stage because of the misalignment. Figure 6 and 7 show that the forces applied along  $x_A$ -axis and  $y_A$ -axis do not exceed 2 lbs because the mating and demating are performed vertically as mentioned above. The mating and demating of the same connector is then repeated under various misalignments. Figure 9 plots the maximum and average mating forces versus the misalignment degrees. As expected, the mating forces are positively proportional to the misalignment degrees as shown in the figure.

## 7 Conclusion

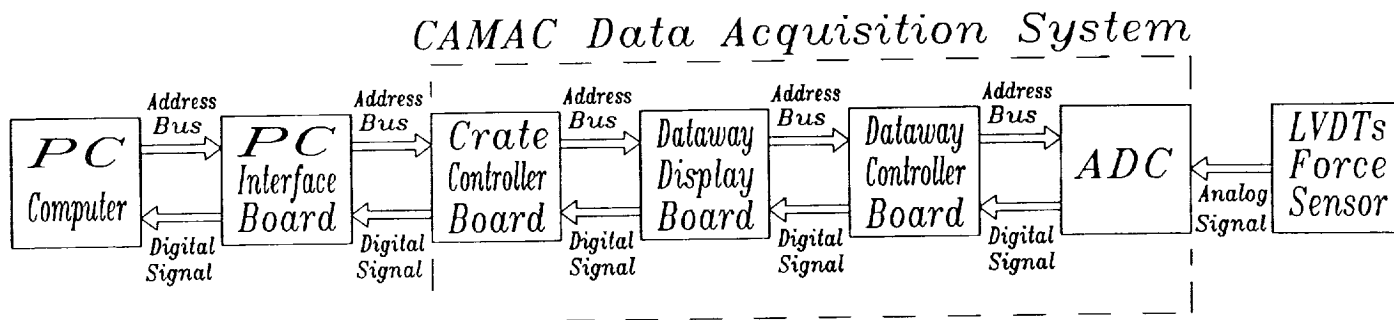
In this report, we have presented the development of the inverse and forward kinematics of a 6 DOF Stewart Platform-based force sensor which is mainly composed of two platforms coupled together by 6 spring-loaded pistons. The force sensor mechanism is also used as a passive compliance device which provides compliance during part assembly tasks. The forces and torques applied to a gripper mounted to the lower compliant platform of the force sensor were computed using the force sensor inverse and forward kinematic equations, the equivalent spring constants and the piston length variations measured by LVDTs mounted along the pistons. Experiments conducted to evaluate the sensing capability of the force sensor showed that it is capable of measuring torque applied to the gripper and of monitoring transient forces applied during the mating and demating of a space-rated connector. The force sensor kinematic equations have been optimized and are currently fast enough for real-time force computation. Future report will report results of experiments such as mating/demating connectors and replacement of orbital replaceable units, which are performed under force feedback.

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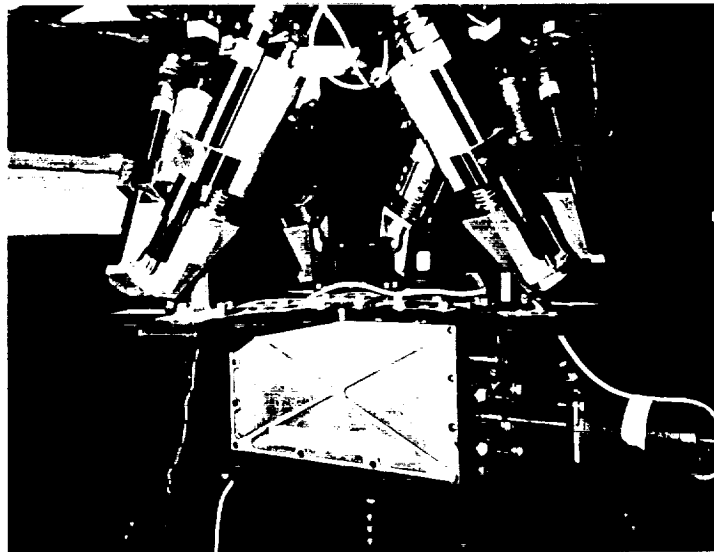
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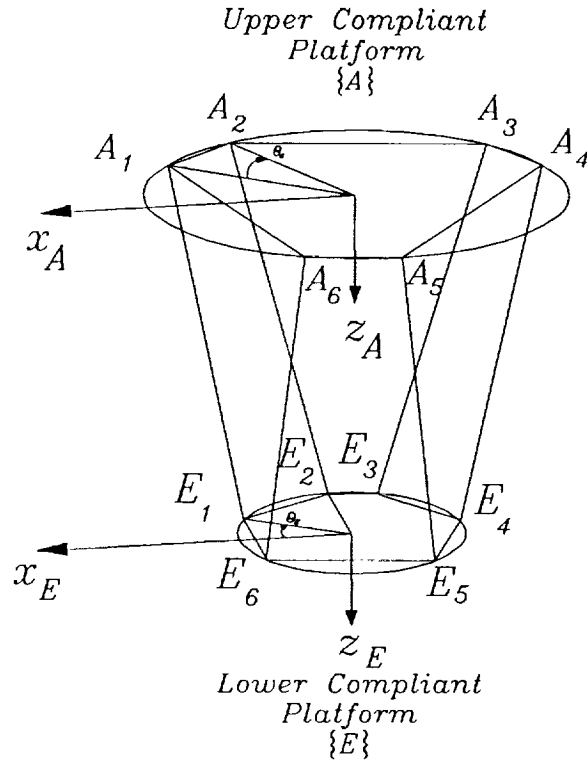
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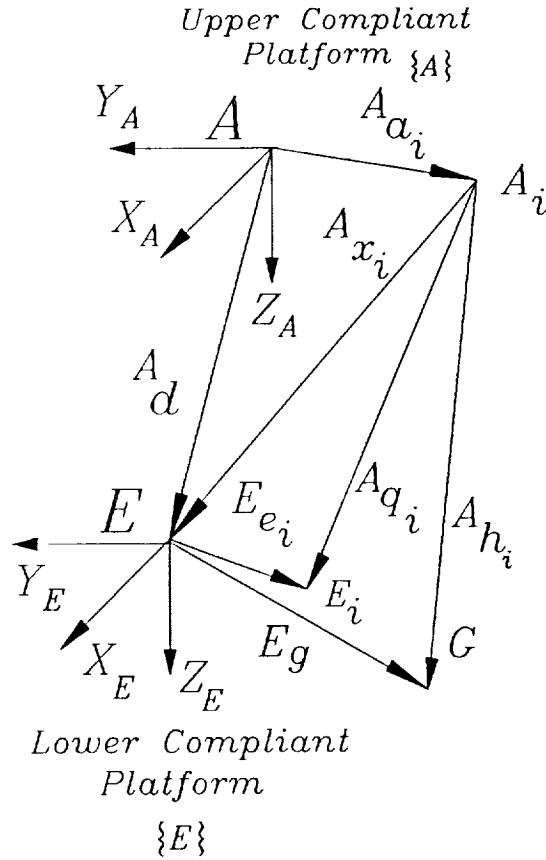
**Figure 1:** The force/torque sensor system



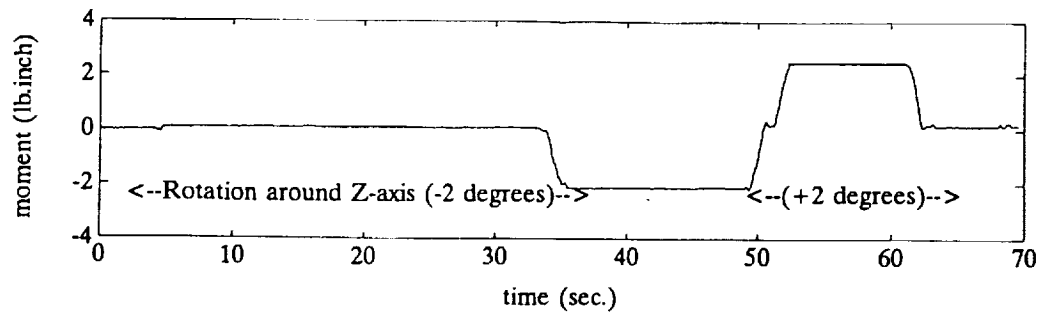
**Figure 2:** The Stewart Platform-based force/torque sensor



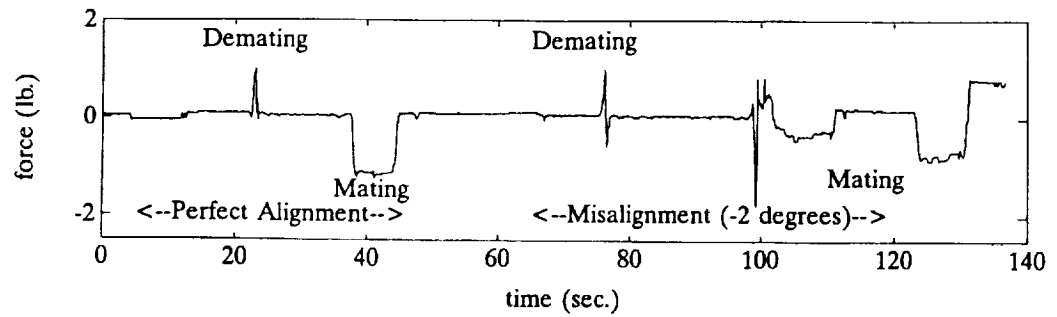
**Figure 3:** Frame assignment for the force/torque sensor



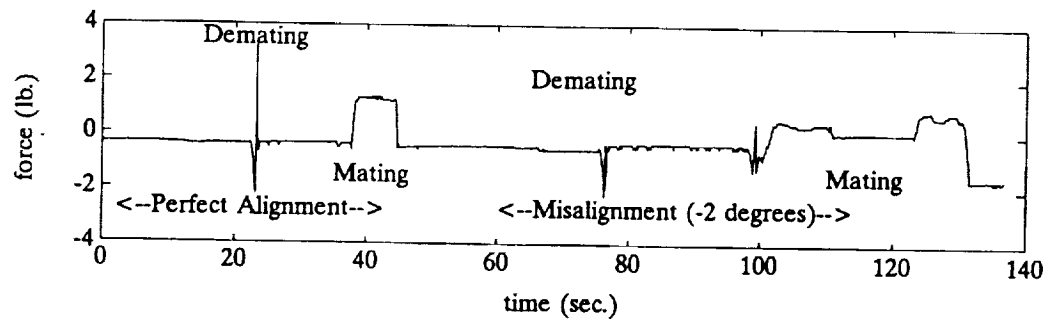
**Figure 4:** Vector diagram of the  $i$ th piston



**Figure 5: Torque about the  $z_G$  axis**

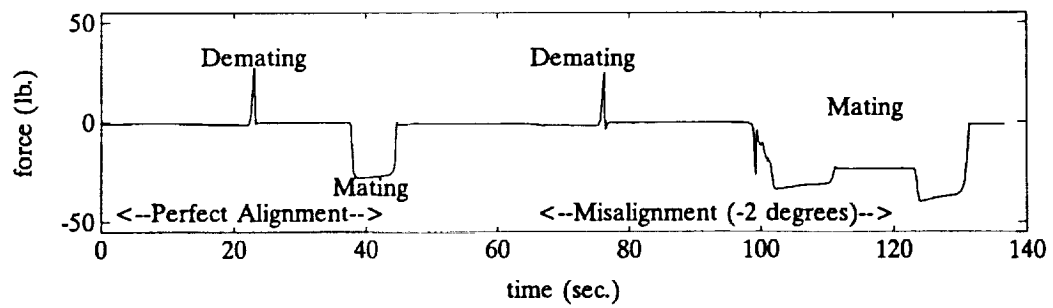


**Figure 6: Force about the  $x_A$  axis**

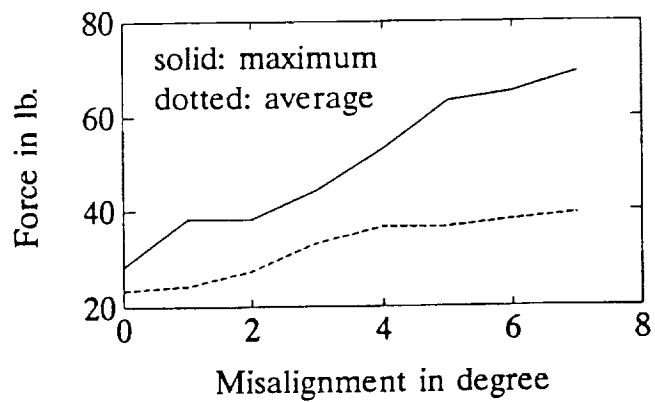


**Figure 7: Force along the  $y_A$  axis**





**Figure 8:** Force along the  $z_A$  axis



**Figure 9:** Mating forces versus misalignment degrees